

Amendments to the Specification:

Please amend the paragraph beginning at page 7, line 31 as follows:

The invention will be explained in greater detail in the description below, with reference to the drawings, in which:

Fig. 1 shows a diagrammatic view of a scara robot known from the prior art;

Fig. 2 shows a diagrammatic view of a delta robot known from the prior art;

Fig. 3a shows a diagrammatic view in perspective of a robot according to the invention;

Fig. 3b shows an exploded view of the robot of Fig. 3a;

Fig. 3c shows an exploded view of the robot of Fig. 3a without actuators;

Fig. 4a shows another diagrammatic view in perspective of the robot of Fig. 3a;

Fig. 4b shows an exploded view of the robot of Fig. 3a according to the view of Fig. 4a;

Fig. 4c shows an exploded view of the robot of Fig. 3a without actuators according to the view of Fig. 4a;

Fig. 5 shows a view in perspective of a robot according to the invention on a mobile frame;

Fig. 6a shows a top view of the robot of Fig. 3a;

Fig. 6b shows a cross section of the robot along the line A-A in Fig. 6a;

Fig. 7a shows an axial section of a shaft member of a gripper for a robot according to the invention;

Fig. 7b shows a cross section along the line A-A in Fig. 7c of the slide of the robot according to the invention;

Fig. 7c shows a cross section of the slide of the robot according to the invention;

Fig. 8 shows a diagrammatic view of a conveyor system provided with a robot according to the invention;

Fig. 9a shows a top view of a detail of a possible belt drive in an idle position of the robot of Fig. 3a;

Fig. 9b shows a top view of the detail of Fig. 9a in a working position, and

Fig. 10 shows a top view of a detail of an alternative belt drive in an idle position of the robot of Fig. 3a, and

Fig. 11 shows a schematic view of a conveyor system according to the invention.

Please amend the paragraph beginning at page 8, line 35 as follows:

The robot 100 further comprises an arm 2, which comprises a second guide 22 (see Fig. 6a [[5]]), which extends in a second direction at an angle relative to the first direction, preferably perpendicularly to the first direction. The second direction is shown in Fig. 4a by a double arrow 102. The arm 2 is supported by way of bearings 21 by the first guide 20a-20c. The arm 2 is movable in the first direction by way of the first guide 20a-20c.

Please amend the paragraph beginning at page 9, line 15 as follows:

Four actuators, preferably the same actuators 6a-6d, are distributed on the base 1, viewed in the first direction. The actuators 6a-6d drive the arm 2, the slide 3 and the gripper 4 by means of pulling elements (see Fig. 4b [[6]]). The pulling elements in the example shown are in the form of endless drive belts 5a-5d. The drive belt 5d is connected to the arm 2 in order to drive said arm in the first direction. Drive belt 5a is connected to the slide 3 in order to drive said slide in the second direction. The drive belts 5c and 5b are connected to the gripper 4 in order to drive said gripper in the third direction or to make it rotate about an axis extending in the third direction, as will be explained in greater detail further on in the description. As indicated in Fig. 4b, the drive belts 5a-5d are guided around by means of pulleys 60a-60d, 61a-61d which are provided on the base. Furthermore, the drive belts 5a-5c are guided around over the arm 2 by pulleys 62a-62c, 63a-63c, 64a-64c and 65a-65c.

Please amend the paragraph beginning at page 13, line 16 as follows:

Such a conveyor system can also comprise several conveyor belts 200 disposed one behind the other and each having one or more robots 100 disposed alongside it. (see Fig. 11)
The conveyor belt 200 disposed furthest downstream is preferably arranged in such a way that

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it moves at a lower speed of conveyance than the conveyor belts disposed more upstream. This means that the last remaining objects 300 remain longer within the reach of the last robot 100, so that the latter is given adequate opportunity to take all objects 300 off the belt 200.